

Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

Claims 1-106. (Cancelled).

107. (Previously Presented) A system for emptying pharmaceutical contents of first pharmaceutical containers including medications into a bulk container storing a first quantity of the pharmaceutical for subsequent dispensing responsive to a patient specific order including a second quantity of the pharmaceutical into a second pharmaceutical container, comprising:

a transport system transporting the first pharmaceutical container;

an information determining system determining information provided on the first pharmaceutical container identifying the first pharmaceuticals contained therein;

a control system determining whether the first pharmaceuticals are authorized to be emptied from the first pharmaceutical container into the bulk container responsive to the determined information received from said information determining system;

a position determining system determining an orientation of the first pharmaceutical container;

an orientation system orientating the first pharmaceutical container responsive to said determining the orientation by said position determining system;

a cutting system cutting the first pharmaceutical container on at least one of the sidewall and bottom of the pharmaceutical container responsive to said orientation received from said orientation system;

a rotating system rotating the cut first pharmaceutical container to empty the first quantity of the contents of the first pharmaceutical container into the bulk container after the first pharmaceutical container is cut by said cutting system;

a determining system determining when the first contents of the first pharmaceutical container are no longer being emptied into the bulk container;

an automated pharmaceutical dispensing system receiving the first contents from the bulk container for subsequent automated dispensing of the pharmaceutical in the second quantity into the second pharmaceutical container responsive to a patient specific prescription order.

108. (New) The system according to claim 107, further comprising a robot for placing the pharmaceutical container in said gripper unit.

109. (New) The system according to claim 108, further comprising a conveyor for transporting the pharmaceutical container in proximity to said robot.

110. (New) The system according to claim 109, further comprising a vision system utilized by said robot to determine the position of the pharmaceutical container on said conveyor.

111. (New) The system according to claim 110, wherein when said vision system does not recognize at least one of the size and shape of a pharmaceutical container, the pharmaceutical container is transported off said conveyor.

112. (New) The system according to claim 111, wherein the bottles transported off of said conveyor are deposited in a bin.

113. (New) The system according to claim 107, wherein the bulk-up container comprises a substantially uniform sized container to facilitate the automated dispensing of the medications.

114. (New) The system according to claim 107, wherein said cutter is an ultrasonic cutter.

115. (New) The system according to claim 107, wherein a rodless air cylinder is used to facilitate movement of said cutter.

116. (New) The system according to claim 107, further comprising an arm that rotates to a first position to receive the cut portion of the pharmaceutical container, and a second position to place the cut portion in a waste repository.

117. (New) The system according to claim 116, wherein said arm utilizes a vacuum that retains the cut portion of said pharmaceutical bottle when said arm is in the first position, and the vacuum decreases when said arm is in the second position to effect release of the cut portion.

118. (New) The system according to claim 117, where the cut portion is released in a scrap bin.

119. (New) The system according to claim 107, further comprising a scrap chute that receives a portion of the pharmaceutical container subsequent to emptying the contents of the pharmaceutical container.

120. (New) The system according to claim 119, wherein said scrap chute is in a distal position with respect to said gripper unit prior to emptying the contents of the pharmaceutical container, said scrap chute moving to a proximal position with respect to said gripper unit to receive the portion of the pharmaceutical container held by the gripper unit subsequent to emptying the contents of the pharmaceutical container, said scrap chute returning to said distal position to place the portion of the pharmaceutical container held by said gripper unit in a scrap bin.

121. (New) The system according to claim 107, further comprising a scrap chute, controlled by said control system, that receives a portion of the pharmaceutical container subsequent to emptying the contents of the pharmaceutical container.

122. (New) The system according to claim 107, further comprising a sensor system to determine when the contents are no longer being emptied directly from the pharmaceutical container.

123. (New) The system according to claim 122, wherein said sensor system comprises a light emitter and a light receiver, said light emitter providing a light beam that is broken by the contents being emptied directly from the pharmaceutical container.

124. (New) The system according to claim 107, wherein said gripper unit comprises first and second interlocking fingers.

125. (New) The system according to claim 124, wherein said first and second interlocking fingers are substantially V-shaped.

126. (New) The system according to claim 124, further comprising a detection system to detect when the pharmaceutical container is no longer being held by said gripper unit.

127. (New) The system according to claim 126, wherein said detection system comprises a light beam source and reflector, said reflector not sensing the light from said light beam source when the pharmaceutical container is held by said gripper unit.

128. (New) The system according to claim 126, wherein the pharmaceutical container can be of different shapes and sizes.

129. (New) The system according to claim 107, further comprising an indicia reader that interfaces with said control system.

130. (New) The system according to claim 129, wherein an indicia associated with a pharmaceutical container is read by said indicia reader, and said control system determining whether said pharmaceuticals are authorized.

131. (New) The system according to claim 107, wherein said control system receives identification information of an operator of the system.

132. (New) The system according to claim 107, further comprising a robot, interfacing with said control system, for placing the pharmaceutical container in said gripper unit.

133. (New) The system according to claim 132, further comprising a vision system, utilized by said robot and interfacing with said control system, to determine the position of the pharmaceutical containers.

134. (New) The system according to claim 107, further comprising a sensor system, interfacing with said control system, to determine when the contents of the pharmaceutical container are no longer being emptied directly from the pharmaceutical container.

135. (New) The system according to claim 107, further comprising a detection system, interfacing with said control system, to detect when the pharmaceutical container is no longer being held by said gripper unit.

136. (New) The system according to claim 107, further comprising a vision system for verifying that the pharmaceutical containers are at least one of the correct diameter and overhead shape.

137. (New) The system according to claim 107, wherein when the pharmaceutical container is placed in the gripper unit, cotton can be removed with at least one of the cutting operation and a robot vacuum.

138. (New) The system according to claim 107, further comprising a non-stick coating on the gripper unit.

139. (New) The system according to claim 107, further comprising a pill accumulation chute.

140. (New) The system according to claim 107, further comprising a light beam unit for verifying that the contents emptied directly from the pharmaceutical container.

141. (New) The system according to claim 107, wherein the cutter cuts off at least one of the top and bottom of the pharmaceutical container.

142. (New) The system according to claim 107, further comprising an electronic viewer for viewing the pharmaceutical container before holding and cutting the pharmaceutical container for providing positioning information of the pharmaceutical container.

143. (New) The system according to claim 143, the control system further comprising verifying user credentials.

144. (New) The system according to claim 107, further comprising a vacuum unit for at least one of providing vacuum flow collecting pill dust and providing vacuum flow in the area of the cutter.

145. (New) A system for emptying pharmaceutical contents of first pharmaceutical containers including medications into a bulk container storing a first quantity of the pharmaceutical for subsequent dispensing responsive to a patient specific order including a second quantity of the pharmaceutical into a second pharmaceutical container, comprising:

a transport system transporting the first pharmaceutical container;

an information determining system determining information provided on the first pharmaceutical container identifying the first pharmaceuticals contained therein;

control system means for determining whether the first pharmaceuticals are authorized to be emptied from the first pharmaceutical container into the bulk container responsive to the determined information received from said information determining system;

a position determining system determining an orientation of the first pharmaceutical container;

an orientation system orientating the first pharmaceutical container responsive to said determining the orientation by said position determining system;

a cutting system cutting the first pharmaceutical container on at least one of the sidewall and bottom of the pharmaceutical container responsive to said orientation received from said orientation system;

a rotating system rotating the cut first pharmaceutical container to empty the first quantity of the contents of the first pharmaceutical container into the bulk container after the first pharmaceutical container is cut by said cutting system;

a determining system determining when the first contents of the first pharmaceutical container are no longer being emptied into the bulk container;

an automated pharmaceutical dispensing system receiving the first contents from the bulk container for subsequent automated dispensing of the pharmaceutical in the second quantity into the second pharmaceutical container responsive to a patient specific prescription order.

146. (New) The system according to claim 145, further comprising a robot for placing the pharmaceutical container in said gripper unit.

147. (New) The system according to claim 146, further comprising a conveyor for transporting the pharmaceutical container in proximity to said robot.

148. (New) The system according to claim 147, further comprising a vision system utilized by said robot to determine the position of the pharmaceutical container on said conveyor.

149. (New) The system according to claim 148, wherein when said vision system does not recognize at least one of the size and shape of a pharmaceutical container, the pharmaceutical container is transported off said conveyor.

150. (New) The system according to claim 149, wherein the bottles transported off of said conveyor are deposited in a bin.

151. (New) The system according to claim 145, wherein the bulk-up container comprises a substantially uniform sized container to facilitate the automated dispensing of the medications.

152. (New) The system according to claim 145, wherein said cutter is an ultrasonic cutter.

153. (New) The system according to claim 145, wherein a rodless air cylinder is used to facilitate movement of said cutter.

154. (New) The system according to claim 145, further comprising an arm that rotates to a first position to receive the cut portion of the pharmaceutical container, and a second position to place the cut portion in a waste repository.

155. (New) The system according to claim 154, wherein said arm utilizes a vacuum that retains the cut portion of said pharmaceutical bottle when said arm is in the first position, and the vacuum decreases when said arm is in the second position to effect release of the cut portion.

156. (New) The system according to claim 155, where the cut portion is released in a scrap bin.

157. (New) The system according to claim 145, further comprising a scrap chute that receives a portion of the pharmaceutical container subsequent to emptying the contents of the pharmaceutical container.

158. (New) The system according to claim 157, wherein said scrap chute is in a distal position with respect to said gripper unit prior to emptying the contents of the pharmaceutical container, said scrap chute moving to a proximal position with respect to said gripper unit to receive the portion of the pharmaceutical container held by the gripper unit subsequent to emptying the contents of the pharmaceutical container, said scrap chute returning to said distal position to place the portion of the pharmaceutical container held by said gripper unit in a scrap bin.

159. (New) The system according to claim 145, further comprising a scrap chute, controlled by said control system means, that receives a portion of the pharmaceutical container subsequent to emptying the contents of the pharmaceutical container.

160. (New) The system according to claim 145, further comprising a sensor system to determine when the contents are no longer being emptied directly from the pharmaceutical container.

161. (New) The system according to claim 160, wherein said sensor system comprises a light emitter and a light receiver, said light emitter providing a light beam that is broken by the contents being emptied directly from the pharmaceutical container.

162. (New) The system according to claim 161, further comprising a detection system to detect when the pharmaceutical container is no longer being held by said gripper unit.

163. (New) The system according to claim 162, wherein said detection system comprises a light beam source and reflector, said reflector not sensing the light from said light beam source when the pharmaceutical container is held by said gripper unit.

164. (New) The system according to claim 145, further comprising a robot, interfacing with said control system means, for placing the pharmaceutical container in said gripper unit.

165. (New) The system according to claim 164, further comprising a vision system, utilized by said robot and interfacing with said control system means, to determine the position of the pharmaceutical containers.

166. (New) The system according to claim 145, further comprising a sensor system, interfacing with said control system means, to determine when the contents of the pharmaceutical container are no longer being emptied directly from the pharmaceutical container.

167. (New) The system according to claim 145, further comprising a detection system, interfacing with said control system means, to detect when the pharmaceutical container is no longer being held by said gripper unit.

168. (New) The system according to claim 145, further comprising a vision system for verifying that the pharmaceutical containers are at least one of the correct diameter and overhead shape.

169. (New) The system according to claim 145, further comprising a light beam unit for verifying that the contents emptied directly from the pharmaceutical container.

170. (New) The system according to claim 145, further comprising an electronic viewer for viewing the pharmaceutical container before holding and cutting the pharmaceutical container for providing positioning information of the pharmaceutical container.

171. (New) The system according to claim 145, further comprising a vacuum unit for at least one of providing vacuum flow collecting pill dust and providing vacuum flow in the area of the cutter.